Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application. Currently amended claims are shown with additions underlined and deletions in ~~strikethrough~~ text. No new matter is added by these amendments.

Listing of Claims:

Claims 1.-18. (Canceled)

19. (Currently amended) A device, comprising:

a moveable member;

an actuator coupled to the moveable member, the actuator being configured to output a haptic feedback, the haptic feedback including a modulating force;

a data storage component configured to store torque data associated with the haptic feedback, the torque data being associated with a plurality of force profiles, the torque data being provided by a host computer based on a selection of at least one force profile from the plurality of force profiles;

a sensor coupled to the moveable member, the sensor being configured to send position information associated with a position of the moveable member; and

a local controller coupled to the data storage component and the actuator, the local controller being configured to be in communication with the host computer, the local controller being configured to send a control signal to the actuator, the control signal being based on data values associated with a host software application of the host computer, the haptic feedback being associated with the position information, and the host software application.

20. (Currently amended)   The device of claim 19, the actuator being a first actuator, the device further comprising a second actuator, the local controller being configured to output the control signal to the first and second actuators, the first and second actuators configured to produce the haptic feedback.

21. (Previously presented) The device of claim 19, wherein the data storage component is configured to receive and store a plurality of torque values from the host computer.

22. (Previously presented) The device of claim 21, wherein each of the torque values is associated with a different tactile sensation.

23. (Currently amended) The device of claim 19, wherein the data storage component is external to the local controller.

24. (Currently amended) The device of claim 19, wherein the data storage component is resident on the local controller.

25. (Currently amended) A device, comprising:

a moveable member, the moveable member being configured to provide haptic feedback based on a plurality of torque data values associated with a processor executable application, the haptic feedback being associated with a plurality of force output profiles, each of the plurality of force output profiles being uniquely associated with a torque data value from the plurality of torque data values;

a local data storage component configured to store the plurality of torque data values, the plurality of torque data values being provided by a host computer based on a selection of a force output profile from the plurality of force output profiles;

a sensor coupled to the moveable member, the sensor being configured to send a position signal associated with a position of the moveable member; and

a local controller coupled to the local data storage component and the sensor, the local controller being configured to control the haptic feedback in response to the position information and based on the plurality of torque data values.

26. (Previously presented) The device of claim 25, wherein the moveable member is a knob, the knob having a plurality of step positions.

27. (Previously presented)   The device of claim 25, wherein the moveable member is at least a portion of an actuator, the actuator being configured to provide the haptic feedback.

28. (Previously presented)   The device of claim 25, wherein the data storage component is external to the local controller.

29. (Previously presented)   The device of claim 25, wherein the data storage component is resident on the local controller.

30. (Previously presented)   The device of claim 25, wherein the local data storage component is configured to receive data from a remote processor.

31. (Currently amended) A method, comprising:

sending a position signal to a local controller, the position signal being based on at least one of a position and a movement of a moveable member;

receiving a control signal, ~~the control signal being~~ associated with at least one of an input signal from a computer program, a_torque signal data from a local memory device, and the position signal, the torque signal data being provided to the local memory device by a host computer based on a selection of a torque profile associated with the torque signal data; and

outputting haptic feedback at the moveable member, the haptic feedback being associated with the control signal.

32. (Currently amended) The method of claim 31, wherein the torque signal data includes a plurality of data values, each data value from the plurality of data values being ~~is~~ associated with different tactile sensations of the haptic feedback.

33. (Currently amended) The method of claim 31, further comprising:

receiving at the local memory device the torque signal data from a host computer, the torque signal data including the input signal.